

FIG. 1

TRACKING ERROR SIGNAL ANALYSIS

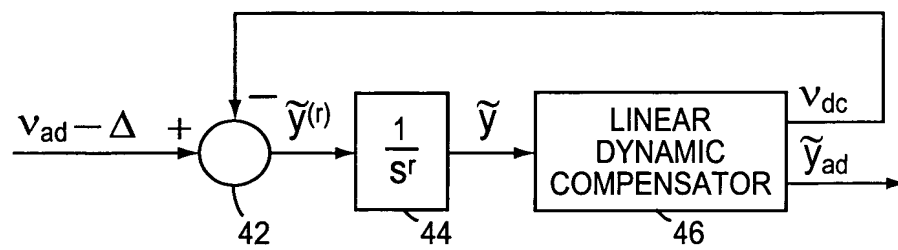


FIG. 2

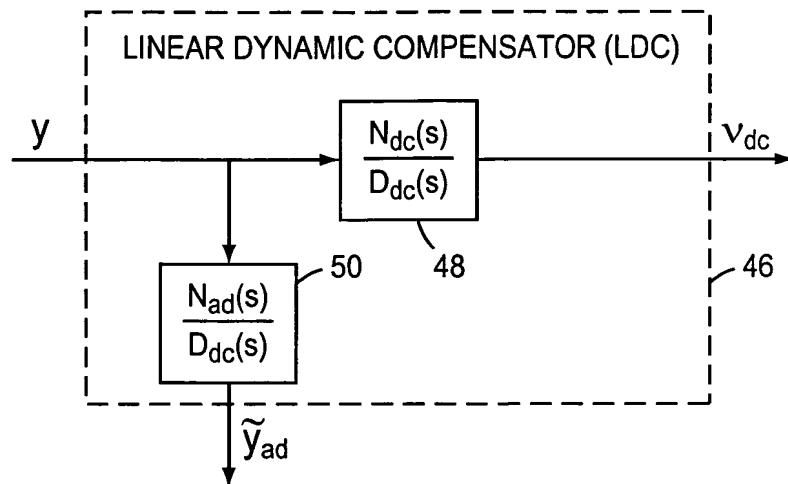


FIG. 3

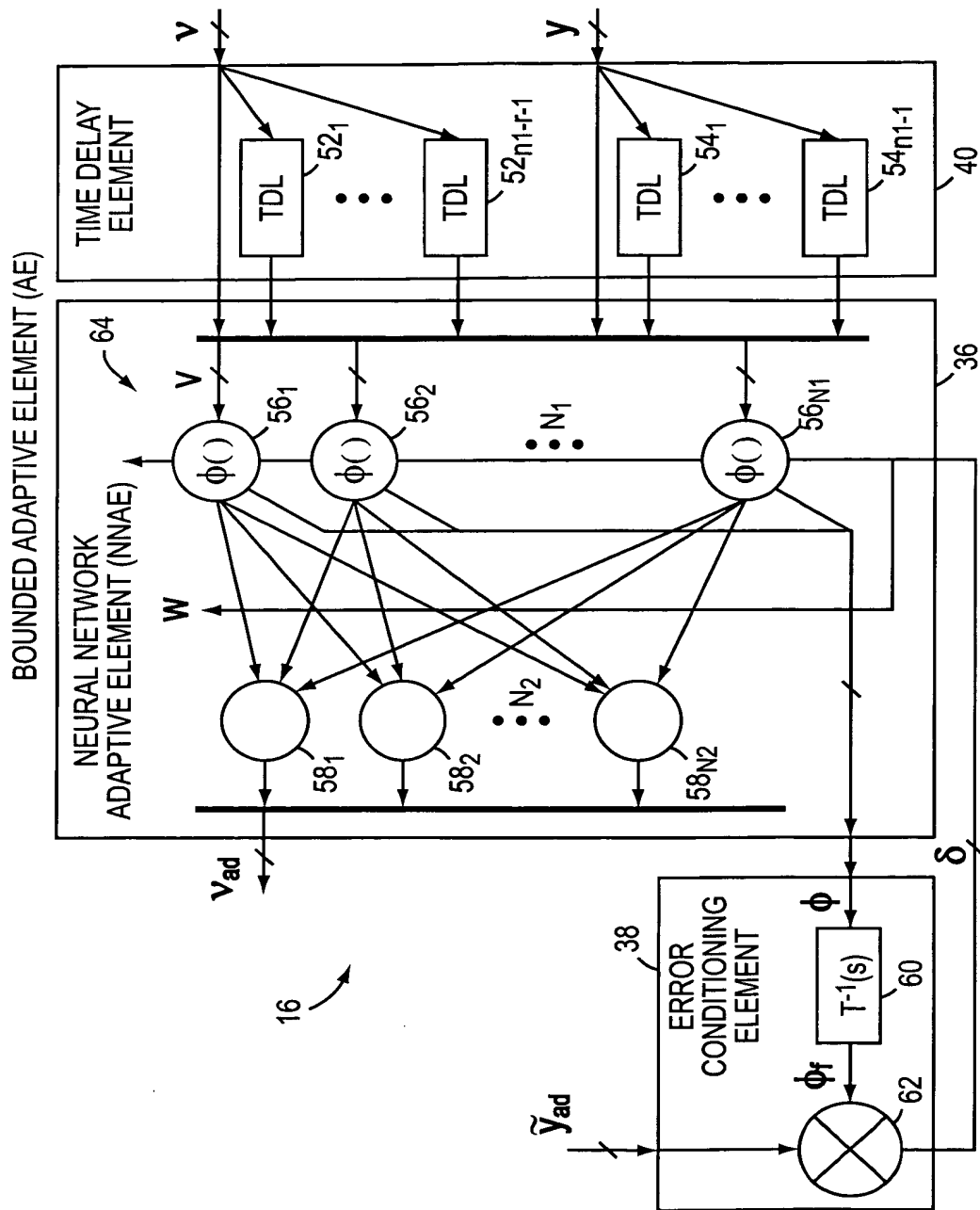


FIG. 4

PROCESSOR-BASED ADAPTIVE CONTROL SYSTEM
USING DIRECT OUTPUT FEEDBACK

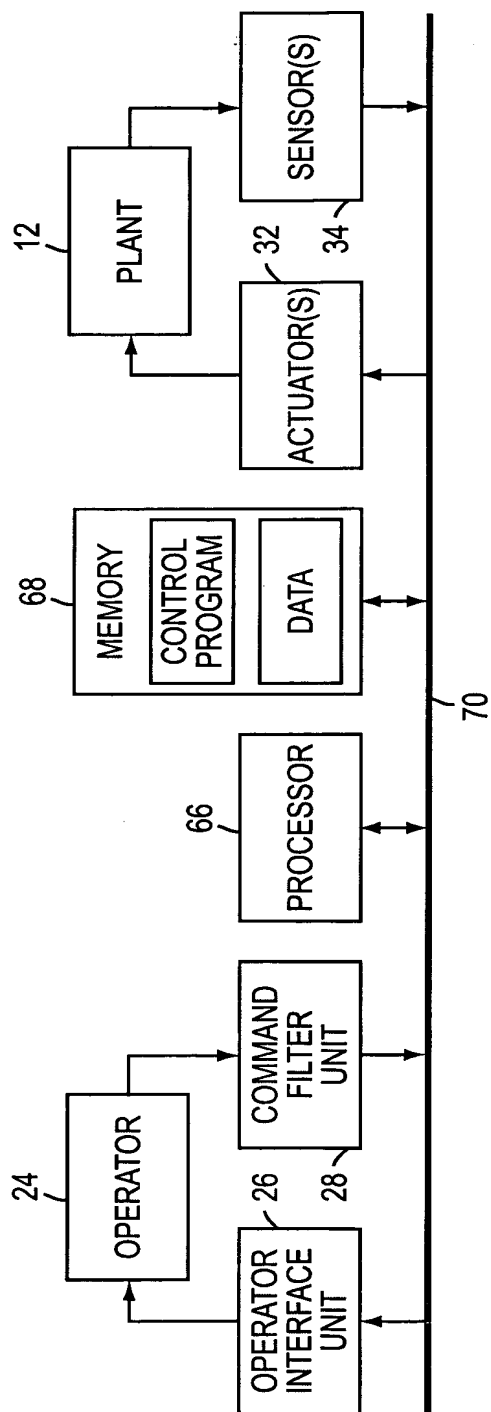


FIG. 5

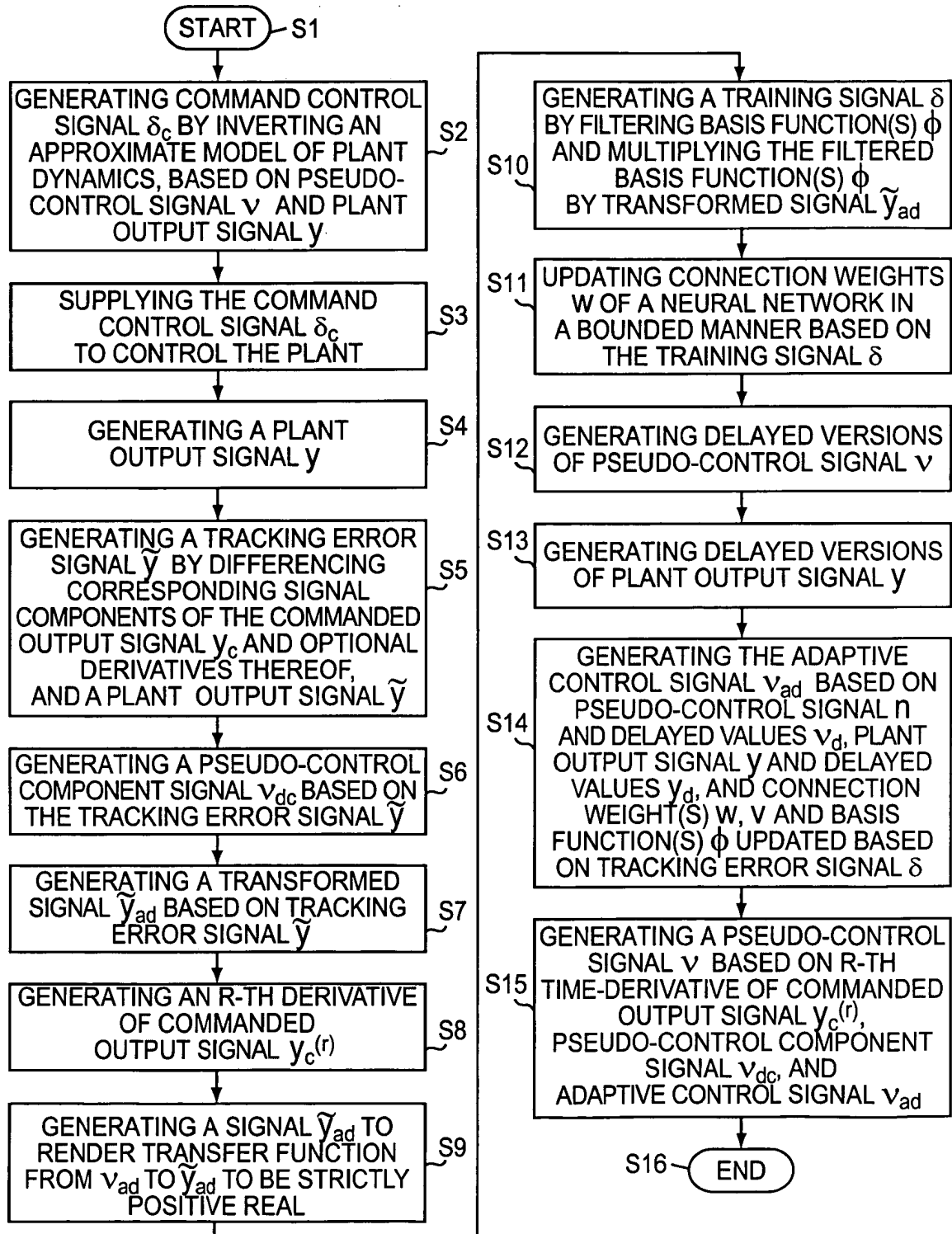
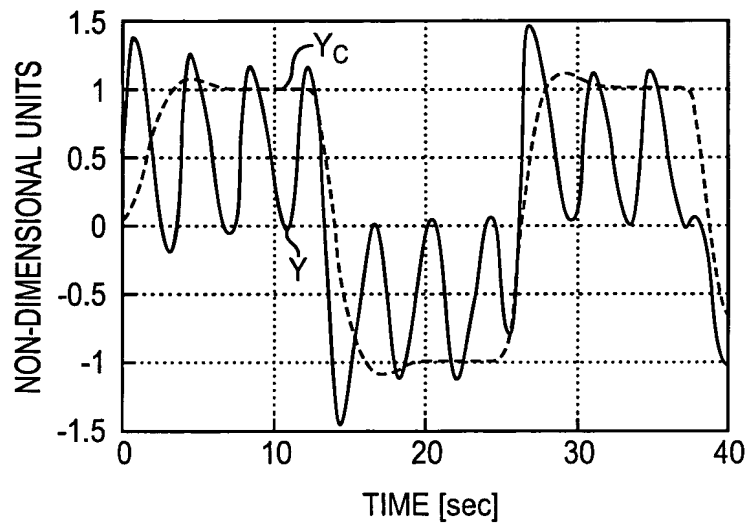


FIG. 6

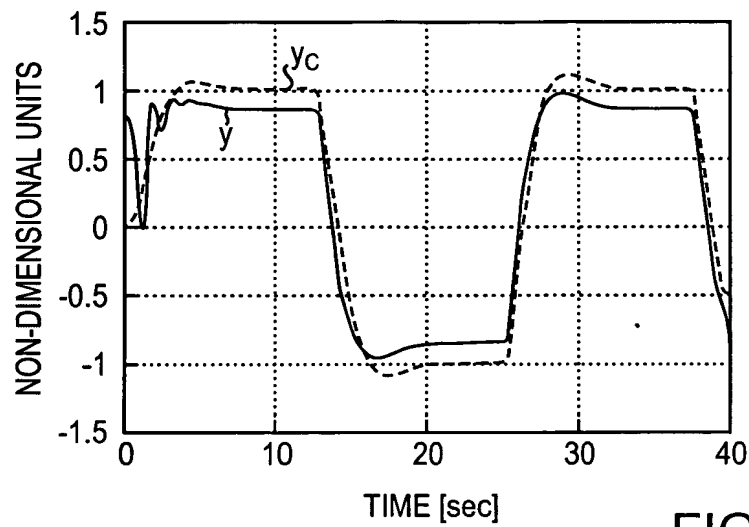
7/10



SYSTEM WITHOUT UNMODELLED DYNAMICS:
RESPONSE WITH LINEAR COMPENSATOR

FIG. 7

SYSTEM WITHOUT UNMODELLED DYNAMICS AND NN CONTROLLER



(a) SYSTEM TRACKING

FIG. 8A

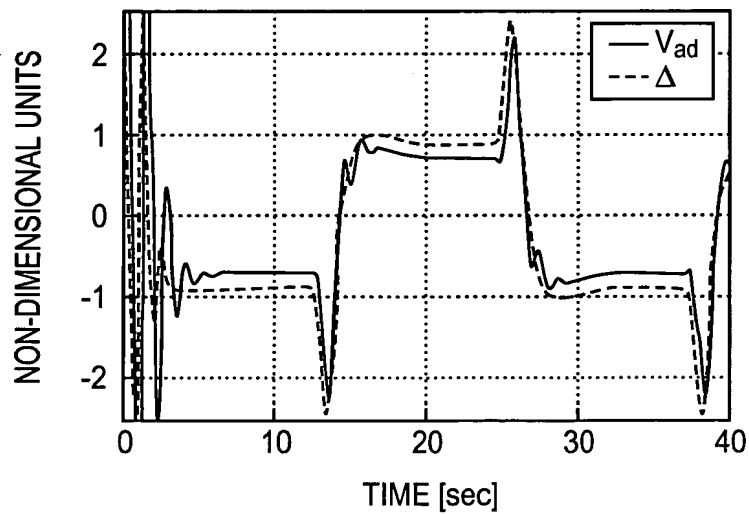
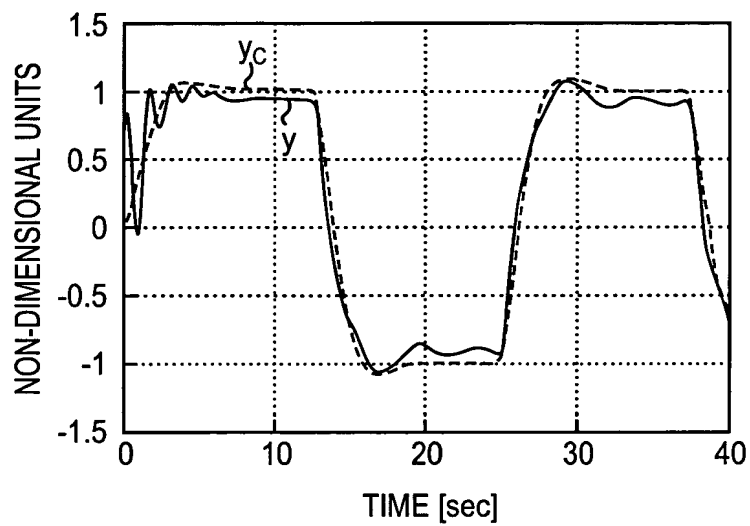
(b) NN OUTPUT V_{ad} AND INVERSION ERROR Δ

FIG. 8B

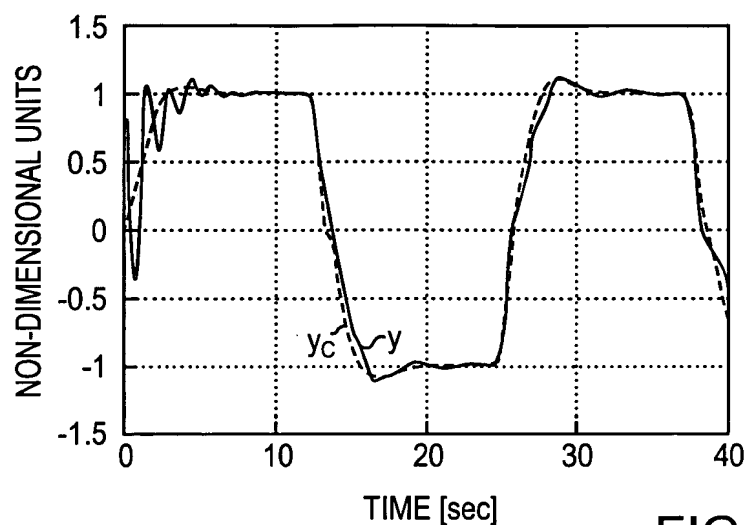


SYSTEM WITH UNMODELLED DYNAMICS:
RESPONSE WITH NN CONTROLLER

FIG. 9

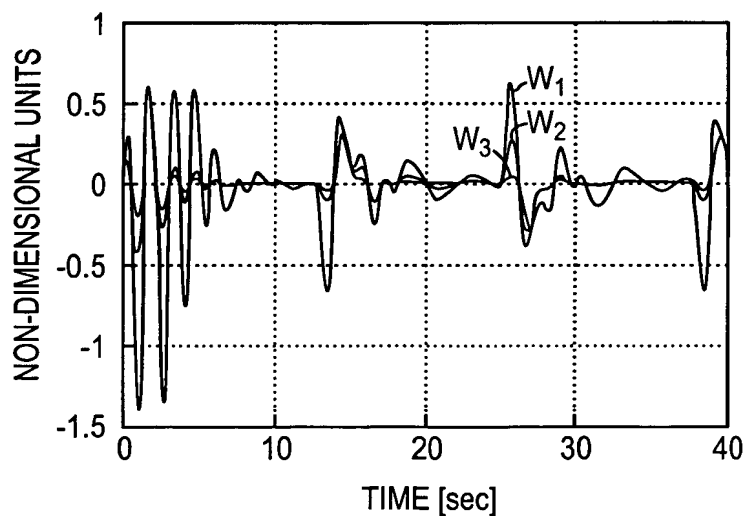
10/10

SYSTEM WITH UNMODELLED DYNAMICS:
RESPONSE WITH NN CONTROLLER AND LINEAR COMPENSATOR



(a) SYSTEM TRACKING

FIG. 10A



(b) NN WEIGHT HISTORY

FIG. 10B